

Abstract

A method and a device are described for determining a future travel-path area of a first vehicle (700), which is furnished with a distance sensor. In this context, using the distance sensor at preestablished or selectable time points, at least relative positions (707, 708) are determined of at least one vehicle traveling ahead (702, 703) with respect to the first vehicle (700). At least these determined relative positions (707, 708) are stored in at least one storage device. These relative positions (707, 708), stored in the storage device, constitute in each case a course path (709, 710) of the corresponding vehicle traveling ahead (702, 703). The future travel-path area of the first vehicle (700) is determined at least on the basis of the course path (709, 710) of the vehicle traveling ahead (702, 703). The course path (709, 710) of the vehicle traveling ahead (702, 703) is projected in the direction of the position of the first vehicle (700).

(Figure 7)